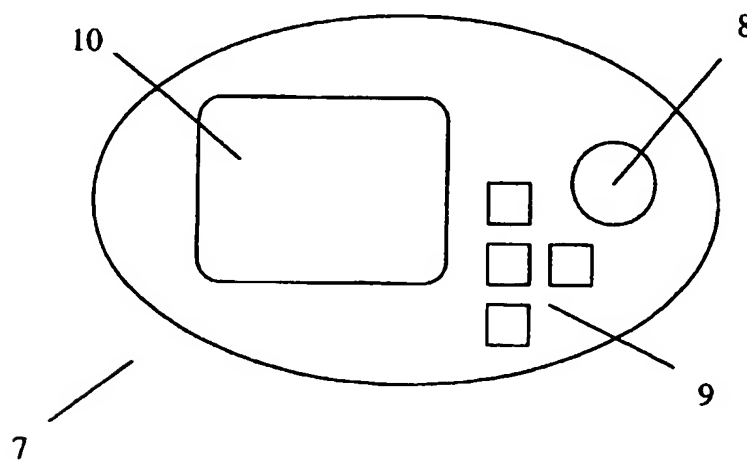
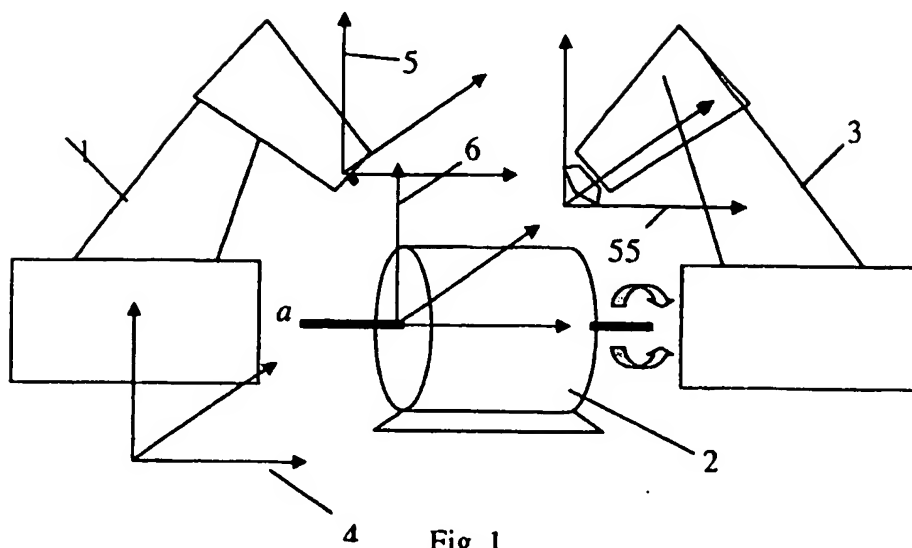


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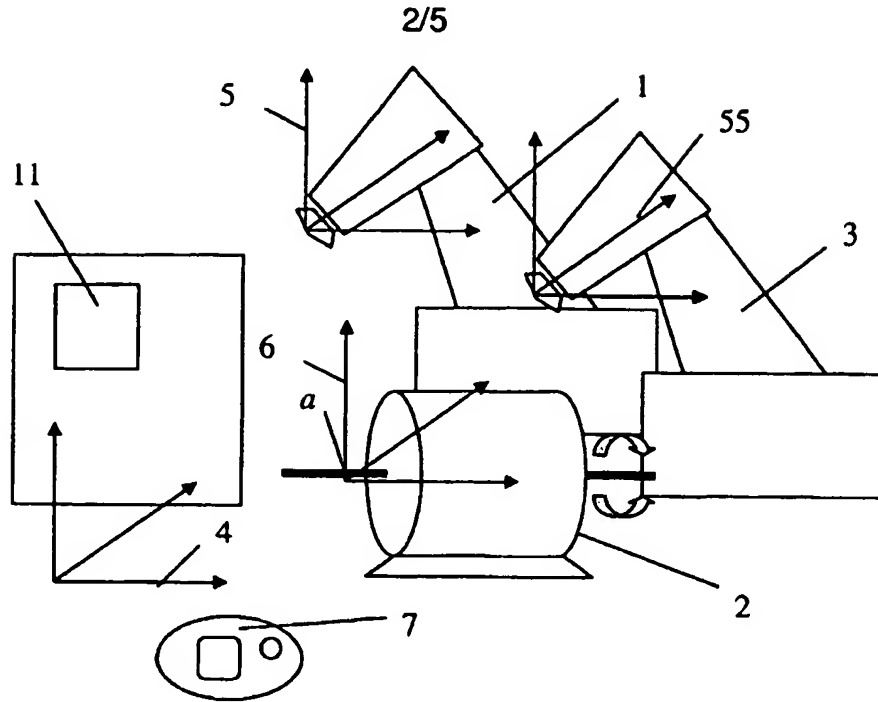


Fig. 3

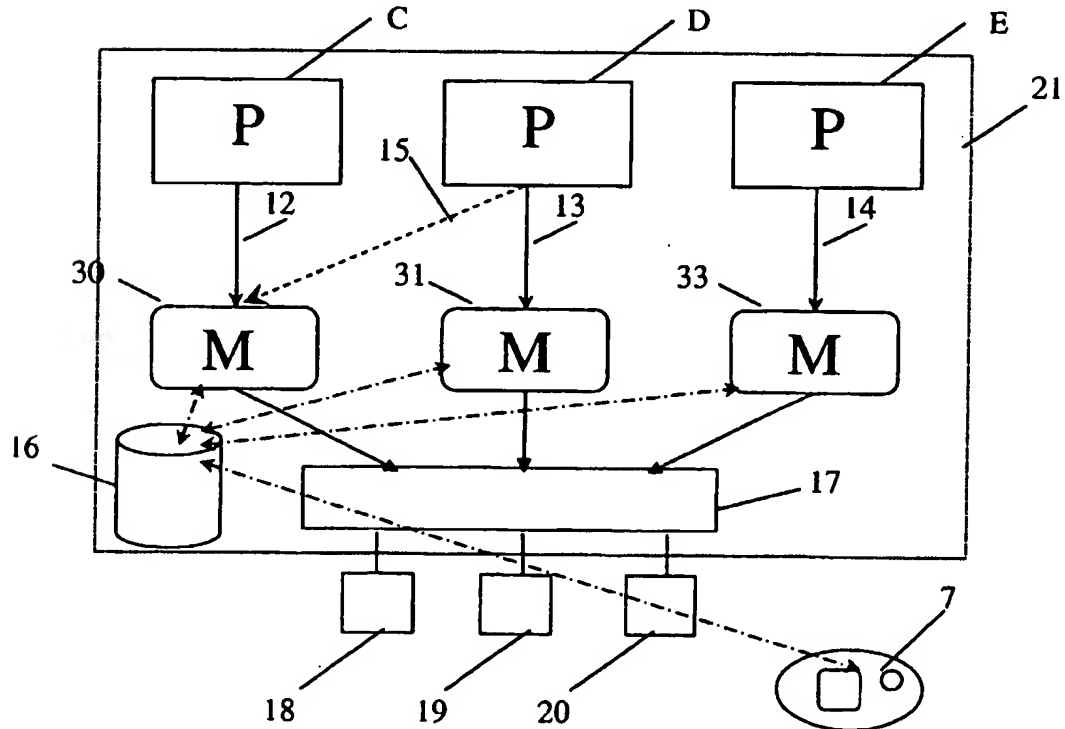


Fig. 4

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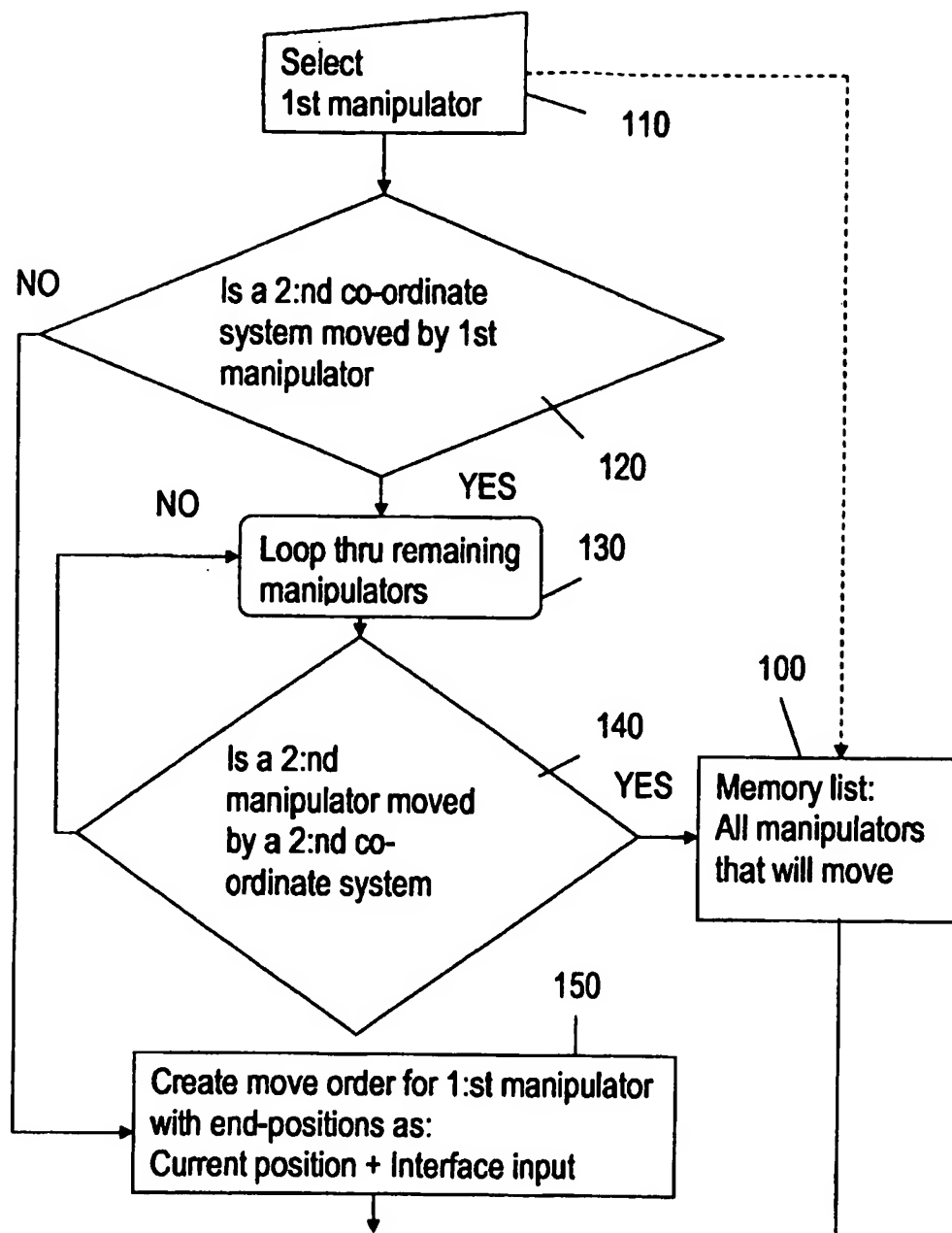


Fig. 5

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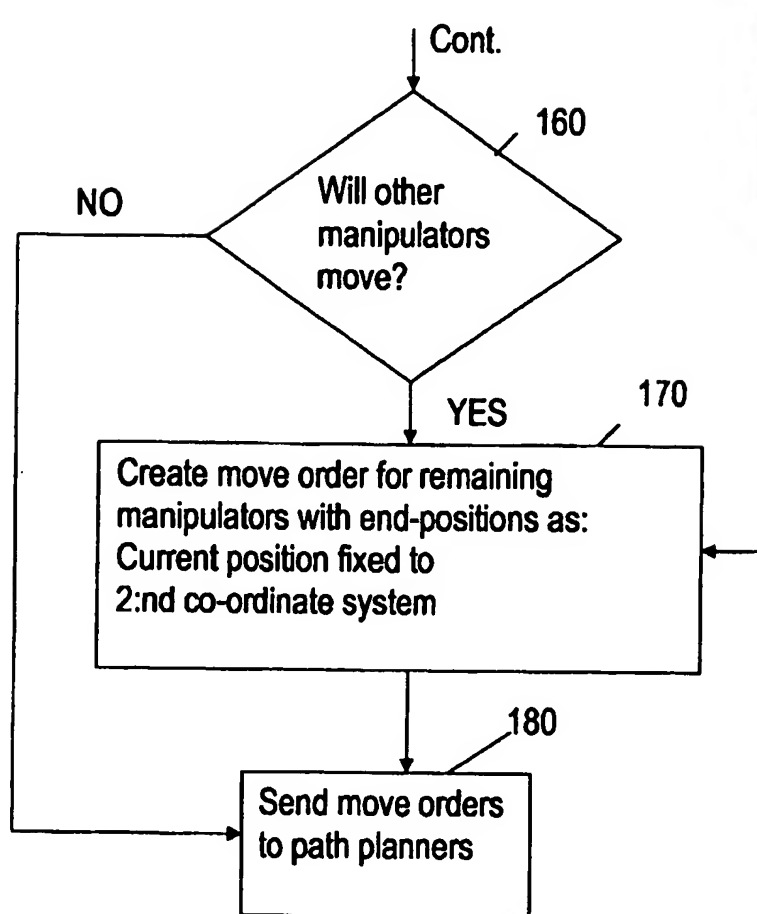


Fig. 5 cont.

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Figure 5 shows a flow chart describing the method according to an embodiment of the invention.

The method comprises the steps of:

- Create a memory list for all manipulators that will move. (100)
- Select first manipulator, go to 100 then 120 (110)
- Is a second co-ordinate system moved by first manipulator, go to 130 else go to 150. (120)
- Loop thru remaining manipulators, (130)
- Is a second manipulator moved by a second co-ordinate system go to 100 else go to 130. (140)
- Create move order for first manipulator with end-positions as: current position and man-machine interface contribution. (150)
- Will other manipulators move? Go to 170 else 180, (160)
- create move order for remaining manipulators with end-positions as: (170)
- Current position fixed to second co-ordinate system.
- Send move orders to path planners. (180)